

generating a correction condition using the plurality of landmarks detected in said detecting step,

generating a virtual image based on the viewing transform condition and the correction condition, and

combining the generated virtual image and the captured image.

REMARKS

Claims 1-3, 6-20, and 22-24 are pending in this application, with Claims 1 and 24 being independent. Claims 4 and 21 have been cancelled herein without prejudice.

Applicants note with appreciation the allowance of Claim 24 by the Examiner. Dependent Claims 22 and 23 have been amended to depend from Claim 24, and therefore Applicants submit that those claims also are allowable.

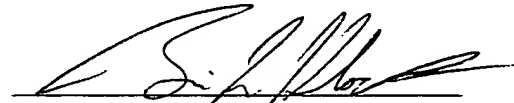
Applicants further note with appreciation the indication that Claim 4 would be allowed if rewritten in independent form. Applicants have effectively done so by cancelling Claim 4 and incorporating the feature of Claim 4 into independent Claim 1. Accordingly, Applicants submit that Claims 1-3 and 6-20 also are allowable, and Applicants request withdrawal of the rejection under 35.U.S.C. §103(a) over U.S. Patent No. 5,764,786 (Kuwashima, et al.) and U.S. Patent No. 6,445,815 (Iijima, et al.).

In view of the foregoing, Applicants submit that this application is in condition for allowance. In particular, since Claim 24 was already allowed and Claim 4 (now incorporated into Claim 1) was indicated as being allowable subject matter, Applicants submit that this Amendment After Final Rejection places the application in clear condition

for allowance. Favorable consideration, entry of this Amendment, and early passage to issue are earnestly solicited.

Applicants' undersigned attorney may be reached in our Washington, DC office by telephone at (202) 530-1010. All correspondence should continue to be directed to our below-listed address.

Respectfully submitted,

A handwritten signature in black ink, appearing to read "B. L. Klock", written over a horizontal line.

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APPENDIX

MARKED-UP VERSION SHOWING AMENDMENTS TO CLAIMS

1. (Currently Amended) A position and orientation determination apparatus which identifies a parameter indicating a position and orientation of a capture unit adapted to capture a picture in a real space containing a plurality of feature points whose positions are known in a three-dimensional array, comprising:

a position and orientation measurement unit adapted to measure the position and orientation of the capture unit in a method other than using a captured picture;

a detection unit adapted to detect the plurality of feature points and their positions in a two-dimensional array on an image pickup screen using the picture in the real space captured by the capture unit;

a prediction unit adapted to predict the positions of the feature points in the two-dimensional array on the image pickup screen based on the position and orientation of the capture unit measured by said position and orientation measurement unit; [and]

a correction unit adapted to correct a parameter of the measured position and orientation of the capture unit based on the positions of the feature points on the image pickup screen of the capture unit obtained by said prediction unit, and based on the positions of the feature points obtained by said detection unit; and

an image generation unit adapted to generate an image of a virtual object based on the corrected parameter, and to superimpose the image of the virtual object on the picture in the real space captured by the capture unit.

22. (Currently Amended) The program code which performs the
information processing [position and orientation determining] method according to claim
24 [21].

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